Amendments to the Specification:

Please replace the paragraph beginning at page 6, line 13 with the following amended paragraph:

Referring to FIGS. 7A and 7B, the user 22a is shown wearing motion sensors 101, over portions of their bodies, and in particular over those portions of the body that exhibit movement. In addition, the mannequins are replaced by robots. For example, a ~~robot 12b~~ robot 12b' includes a series of motion actuators 103. Each motion actuator 103 placement corresponds to a motion sensor 101 on the user 22a so that each motion sensor activates a motion actuator in the robot that makes the corresponding movement.

Please replace the paragraph beginning at page 6, line 13 with the following amended paragraph:

For example, when the user 22a moves their right hand, a sensor in the right hand sends a signal through the network to a motion actuator on the ~~robot~~ robot 12b'. The ~~robot 12b~~ robot 12b' in turn moves its right hand.

Please replace the paragraph beginning at page 6, line 26 with the following amended paragraph:

In another example, a user 22a can walk towards a ~~robot 12a~~ robot 12a' in location A. All the sensors on the user 22a send a corresponding signal to the actuators on the ~~robot 12b~~ robot 12b' in location B. The ~~robot 12b~~ robot 12b' in location B performs the same walking movement. The user 22b in location B is not looking in location B but rather through the eyes of the ~~robot 12a~~ robot 12a' in location A so that user 22b does see the user 22a in location A walking towards them, but not because the ~~robot 12b~~ robot 12b' in location B is walking. However, the fact that the ~~robot 12b~~ robot 12b' in location B is walking enables two things to happen. First, since the user 22a in location A is seeing through the eyes of the ~~robot 12b~~ robot 12b' in location B and since the ~~robot 12b~~ robot 12b' in location B is walking enables the user

22a in location A to see what he would see if he were indeed walking in location B. Second, it enables the robot 12b robot 12b' in location B to meet up with the user 22b in location B.

Please replace the paragraph beginning at page 8, line 16 with the following amended paragraph:

Referring to FIGS. 8A and 8B, in still other embodiments, tactile sensors 104 are placed on the exterior of a robot hand 102 located in Location A. Corresponding tactile actuators 106 are sewn into an interior of a glove 104 107 worn by a user in location B. Using system 10, a user in location B can feel objects in Location A. For example, a user can see a vase within a room, walk over to the vase, and pick-up the vase. The tactile sensors–actuators are sensitive enough so that the user can feel the texture of the vase.

Please replace the paragraph beginning at page 8, line 26 with the following amended paragraph:

Referring to FIGS. 11A and 11B, in other embodiments, a user 22a can receive a morphed image 304 of user 22b. For example, an image 302 of user 22b is transmitted through network 24 to communications gateway 16a. User 22b has brown hair, brown eyes and a large nose. Communications gateway 16a again using conventional imaging morphing techniques alters the image of user 22b so that user 22b has blond hair, blue eyes and a small noise nose and sends that image to goggles 20a to be rendered.

Please delete the Title "VIRTUAL REALITY ENCOUNTERS" on the abstract page, at page 16.